

CLAIMS:

1. Control arrangement for controlling a plurality of Lorenz motors (1, 2) actuating a payload (4), the payload having a center of gravity (12), the control arrangement comprising a controller (8) for receiving height signals (z_1 , z_2) from sensors sensing heights of said payload and for calculating control signals (C_1 , C_2) for said Lorenz motors from said height signals, characterized in that said controller (8) is arranged to calculate from these height signals (z_1 , z_2) at least one angle of rotation of the center of gravity about a horizontal axis and calculate from this at least one angle of rotation said control signals (C_1 , C_2) for said Lorenz motors (1, 2) such that a predetermined rotational stiffness for supporting said payload (4) is achieved.
2. Control arrangement according to claim 1, wherein said controller (8) is arranged to control three or four Lorenz motors.
3. Method of controlling a plurality of Lorenz motors (1, 2) actuating a payload (4), the payload having a center of gravity (12), the method comprising receiving height signals (z_1 , z_2) from sensors sensing heights of said payload and calculating control signals (C_1 , C_2) for said Lorenz motors from said height signals, characterized by calculating from these height signals (z_1 , z_2) at least one angle of rotation of the center of gravity about a horizontal axis and calculating from this at least one angle of rotation said control signals (C_1 , C_2) for said Lorenz motors (1, 2) such that a predetermined rotational stiffness for supporting said payload (4) is achieved.
4. Computer program product comprising instructions and data to be loaded by a computer, and after being loaded allowing the computer to perform the method according to claim 3.
5. Data carrier comprising a computer program product according to claim 4.